

Amendments to the Claims

1. (Currently Amended) A method to design a feedback controller for extracting acoustic energy and structural energy in an acoustic enclosure comprising the steps of:

obtaining a continuous-time multi-input multi-output state-space mathematical model of the acoustic enclosure;

designing compensation to render the mathematical model passive in accordance with mathematical system theory if the mathematical model is not passive, thereby forming a compensated system that is passive;

checking passivity of the compensated system; and

designing a passivity-based controller that extracts at least one of acoustic energy or structural energy such that a resulting closed-loop response provides a desired noise reduction.

2. (Canceled).

3. (Currently Amended) The method of claim 1 wherein the step of obtaining a continuous-time multi-input multi-output state-space mathematical model of the acoustic enclosure comprises the step of obtaining a mathematical model having the form according to the equation

$$E\dot{x}(t) = Ax(t) + Bu(t) + Df(t)$$

where A , B , D , and E are matrices given by

$$\underline{E} = \begin{bmatrix} E_{11} & 0 \\ E_{21} & E_{22} \end{bmatrix} \quad \underline{A} = \begin{bmatrix} A_{11} & 0 \\ 0 & A_{22} \end{bmatrix}$$

$$\underline{B} = \frac{1}{h\rho_0 S_1} \begin{bmatrix} B_{11} \\ 0 \end{bmatrix} \quad \underline{D} = \frac{1}{h\rho_0} \begin{bmatrix} D_{11} \\ 0 \end{bmatrix}$$

where $E_{11} = \mathbf{I}$ and $A_{11} = \text{diag}(A_{11}^{nm})$ are square matrices of order $p_1 p_2$, $E_{22} = \mathbf{I}$ and $A_{22} = \text{diag}(A_{22}^{k_1 k_2 k_3})$ are square matrices of order $(l_1 + 1)(l_2 + 1)(l_3 + 1)$, B_{11} is a $p_1 p_2 \times$

r matrix, D_{11} is a $p_1 p_2 \times 1$ matrix where matrices E_{21} , A_{11} , A_{22} , B_{11} , and D_{11} are given by

$$E_{21} = -\frac{c_0^2 \rho_0}{V} \begin{bmatrix} 0 & 0 & \cdots 0 & 0 \\ 0 & \alpha_{00111} & \cdots 0 & \alpha_{001 p_1 p_2} \\ \cdots & \cdots & \cdots & \cdots \\ 0 & 0 & \cdots 0 & 0 \\ 0 & \alpha_{i_1 i_2 i_3 11} & \cdots 0 & \alpha_{i_1 i_2 i_3 p_1 p_2} \end{bmatrix}$$

$$A_{11}^{nm} = \begin{bmatrix} 0 & 1 \\ -\omega_{nm}^2 & -2\zeta_{nm} \omega_{nm} \end{bmatrix}$$

$$A_{22}^{k_1 k_2 k_3} = \begin{bmatrix} 0 & 1 \\ -\omega_{k_1 k_2 k_3}^2 & -2\zeta_{k_1 k_2 k_3} \omega_{k_1 k_2 k_3} \end{bmatrix}$$

$$B_{11} = \begin{bmatrix} 0 & \cdots & 0 \\ \phi_{11}(x_{11}, y_{11}) & \cdots & \phi_{11}(x_{1r}, y_{1r}) \\ \cdots & \cdots & \cdots \\ 0 & \cdots & 0 \\ \phi_{p_1 p_2}(x_{11}, y_{11}) & \cdots & \phi_{p_1 p_2}(x_{1r}, y_{1r}) \end{bmatrix}$$

$$D_{11} = \begin{bmatrix} 0 \\ \gamma_{11} \\ \cdots \\ 0 \\ \gamma_{p_1 p_2} \end{bmatrix}$$

where h is a thickness of the enclosure, ρ_0 is fluid density at equilibrium, S_1 is a boundary surface of the structure, c_0 is the sound speed, V is the volume of the enclosure, α 's are coupling coefficients describing the modal interaction between structural and acoustic modes, ω_{ij} denotes natural frequency related to ij -th mode for the structure, ω_{ijk} denotes the acoustical modal frequency for the ijk -th acoustic mode of the enclosure, ζ_{ij} is the damping of the ij -th structural mode shape, ζ_{ijk} is the damping of the ijk -th acoustical mode shape, ϕ_{ij} is the ij -th mode shape of the enclosure structure, and γ_{ij} in matrix D_{11} indicate non-zero coefficients for the direct transmission terms which are functions of modal parameters.

4. (Currently Amended) The method of claim 1 wherein the step of designing a passivity-based controller includes designing a controller having a transfer function $G(s)$ wherein

$$G(s) = Js^2 \sum_{k_1=0}^{l_1} \sum_{k_2=0}^{l_2} \sum_{k_3=0}^{l_3} \frac{\psi_{k_1 k_2 k_3}(x, y, z)}{s^2 + 2\zeta_{k_1 k_2 k_3} \omega_{k_1 k_2 k_3} s + \omega_{k_1 k_2 k_3}^2} \left[\sum_{n=1}^{p_1} \sum_{m=1}^{p_2} \frac{\alpha_{k_1 k_2 k_3 nm} \phi_{nm}(x_{11}, y_{11})}{s^2 + 2\zeta_{nm} \omega_{nm} s + \omega_{nm}^2} \right]$$

where $J = \frac{c_0^2 \rho_0}{V h \rho_p S_1}$, h is a thickness of the enclosure, ρ_0 is fluid density at equilibrium, S_1 is

a boundary surface of the structure, c_0 is the sound speed, ρ_p is the density of the plate, $\psi_{k_1 k_2 k_3}(x, y, z)$ are normal modes of a non-homogeneous wave equation,

$\omega_{k_1 k_2 k_3} = c_0 \sqrt{\xi_{k_1}^2 + \xi_{k_2}^2 + \xi_{k_3}^2}$ with ξ_{k_1} , ξ_{k_2} and ξ_{k_3} being modal coordinates, ζ_{ijk} is the damping of the ijk -th acoustical mode shape, α 's are coupling coefficients describing the modal interaction between structural and acoustic modes, and ζ_{ij} is the damping of the ij -th structural mode shape.

5. (Currently Amended) The method of claim 1 wherein the acoustic enclosure has a soft boundary and the step of designing a passivity-based controller includes designing a controller having a transfer function $G_{sb}(s)$ wherein

$$G_{sb}(s) = \frac{1}{i=1} \frac{\rho_0 s^2 c_0^2}{h \rho_p S_1} \cdot \frac{\Psi_i(r_0)}{s^2 + \rho_0 c_0^2 s D_{ii}(s) + c_0^2 B_{ii}} \cdot \left[\sum_{n=1}^{p_1} \sum_{m=1}^{p_2} \frac{\eta_{nm} \phi_{nm}(x_{11}, y_{11})}{s^2 + 2\zeta_{nm} \omega_{nm} s + \omega_{nm}^2} \right]$$

where Ψ_j denotes the eigenmode function for the acoustic pressure expression obtained using the assumed modes method, η_{sum} is the volume integral term consisting of integrand which is product of structural-acoustic eigenfunctions, ζ_{ij} is the damping of the ij -th structural mode shape, ρ_0 is fluid density at equilibrium, c_0 is the sound speed, S_1 is a boundary surface of the structure, h is a thickness of the enclosure, ρ_p is the density of the plate, ϕ_{ij} is the ij -th mode shape of the enclosure structure, and

$$D_{ij}(s) = \int_S \frac{\Psi_j(s)\Psi_i(s)}{Z(r,s)} dS, \quad \beta_{ij}(s) = \int_V \nabla \Psi_j(r) \nabla \Psi_i(r) dV \quad \text{where } Z \text{ is the impedance.}$$

6. (Currently Amended) The method of claim 1 wherein the step of designing compensation includes the step of designing a series passifier $C_s(s)$ according to $C_s(s) \approx \begin{cases} \dot{x}_c = A_c x_c + B_c u \\ u' = C_c x_c + D_c u \end{cases}$ wherein A_c , B_c , C_c , and D_c are determined according to the steps comprising:

$$\text{solving the equation } \begin{bmatrix} A^{**} & (*) & (*) \\ \hat{A} + A^T & YA + A^T Y & (*) \\ \hat{D}^T B^T - C\hat{X} - D\hat{C} & \hat{B}^T - C & D^{**} \end{bmatrix} < 0 \quad \text{to obtain}$$

$X, Y, \hat{A}, \hat{B}, \hat{C}$, and \hat{D} ;

constructing matrices M , N , and P such that

$$P\Pi_1 = \Pi_2 \quad \text{and} \quad \Pi_1^T \Pi_2 = \begin{bmatrix} X & I \\ I & Y \end{bmatrix} \quad \text{where } XY + MN^T = I,$$

$$\Pi_1 = \begin{bmatrix} X & I \\ M^T & 0 \end{bmatrix}, \quad \Pi_2 = \begin{bmatrix} I & Y \\ 0 & N^T \end{bmatrix}, \quad P = \begin{bmatrix} Y & N \\ N^T & * \end{bmatrix}; \quad \text{and}$$

solving the equations $\hat{A} = YAX + YBC_c M^T + NA_c M^T$, $\hat{B} = YBD_c + NB_c$, $\hat{C} = C_c M^T$, and $\hat{D} = D_c$ in reverse order to obtain A_c , B_c , C_c , and D_c .

7. (Currently Amended) The method of claim 1 wherein the step of designing compensation comprises the step of designing a feedforward compensator

$C_{ff}(s)$ according to $C_{ff}(s) \approx \begin{cases} \dot{x}_c = A_c x_c + B_c u \\ y_2 = C_c x_c + D_c u \end{cases}$ wherein A_c , B_c , C_c , and D_c are

determined according to the steps comprising:

$$\text{solving the equation } \begin{bmatrix} AX + XA^T & (*) & (*) \\ \hat{A} + A^T & YA + A^T Y & (*) \\ B^T - CX - \hat{C} & B^T Y + \hat{B}^T - C & D^\perp \end{bmatrix} < 0 \text{ where}$$

$D^\perp = -(D + D^T + \hat{D} + \hat{D}^T)$ to obtain $X, Y, \hat{A}, \hat{B}, \hat{C}$, and \hat{D} ;

constructing matrices M , N , and P such that

$$P\Pi_1 = \Pi_2 \text{ and } \Pi_2^T \tilde{A}\Pi_1 = \begin{bmatrix} AX & A \\ YAX + NA_c M^T & YA \end{bmatrix} \text{ where } XY + MN^T = I,$$

$$\Pi_1 = \begin{bmatrix} X & I \\ M^T & 0 \end{bmatrix}, \Pi_2 = \begin{bmatrix} I & Y \\ 0 & N^T \end{bmatrix}, P = \begin{bmatrix} Y & N \\ N^T & * \end{bmatrix}; \text{ and}$$

solving the equations $\hat{A} = YAX + NA_c M^T$, $\hat{B} = NB_c$, $\hat{C} = C_c M^T$, and $\hat{D} = D_c$ in reverse order to obtain A_c , B_c , C_c , and D_c .

8. (Original) The method of claim 1 wherein the step of designing compensation comprises the step of performing sensor blending if there are redundant sensors.

9. (Original) The method of claim 1 wherein the step of designing compensation comprises the step of performing control allocation if there are redundant actuators.

10. (Original) The method of claim 1 wherein the step of designing compensation to render the mathematical model passive comprises the steps of:

determining if a feedforward compensation will passify the system;

if a feedforward compensation will not passify the system:

designing a constant gain feedforward compensation to render the compensated system minimum-phase; and

rendering the compensated system positive-real by at least one of series compensation, sensor-blending and control allocation.

11. (Original) The method of claim 10 wherein the step of designing a passivity-based controller comprises the step of designing one of a dissipative linear-quadratic-Gaussian (LQG) type positive-real controller and a dissipative constant gain positive-real controller.

12. (Original) The method of claim 10 wherein the step of rendering the compensated system positive-real by at least one of series compensation, sensor-blending and control allocation comprises the step of rendering the compensated system positive-real by at least one of series compensation, feedback compensation, hybrid compensation, and sensor-blending and control allocation.

13. (Currently Amended) The method of claim 1 further comprising the step of redesigning the compensation if the passivity is not preserved ~~if mathematical model parameters are perturbed from nominal values.~~

14.(Currently Amended) The method of claim 1 further comprising the step of performing numerical simulations of the controller in the presence of a simulated broadband disturbance input ~~to determine if the closed-loop response is satisfactory.~~

15. (Original) The method of claim 14 further comprising the step of redesigning the controller if the closed-loop response is not satisfactory.

16. (Original) The method of claim 1 wherein the step of designing compensation comprises the steps of:

designing a constant gain feedforward compensation to render the compensated system minimum-phase; and

rendering the compensated system positive-real by one of sensor-blending and control allocation.